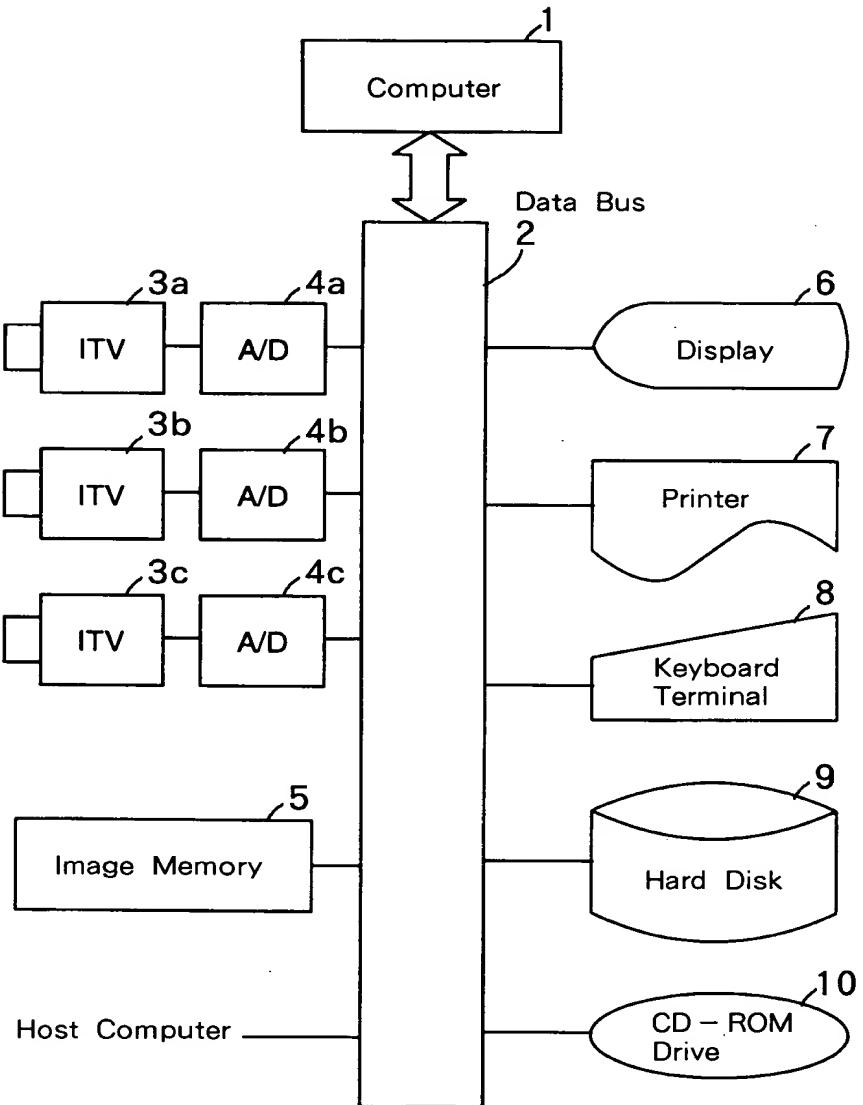


FIG. 1

System Configuration for Embodying the Present Invention



00000000000000000000000000000000

FIG.2

Flow of Basic Processing of This Invention

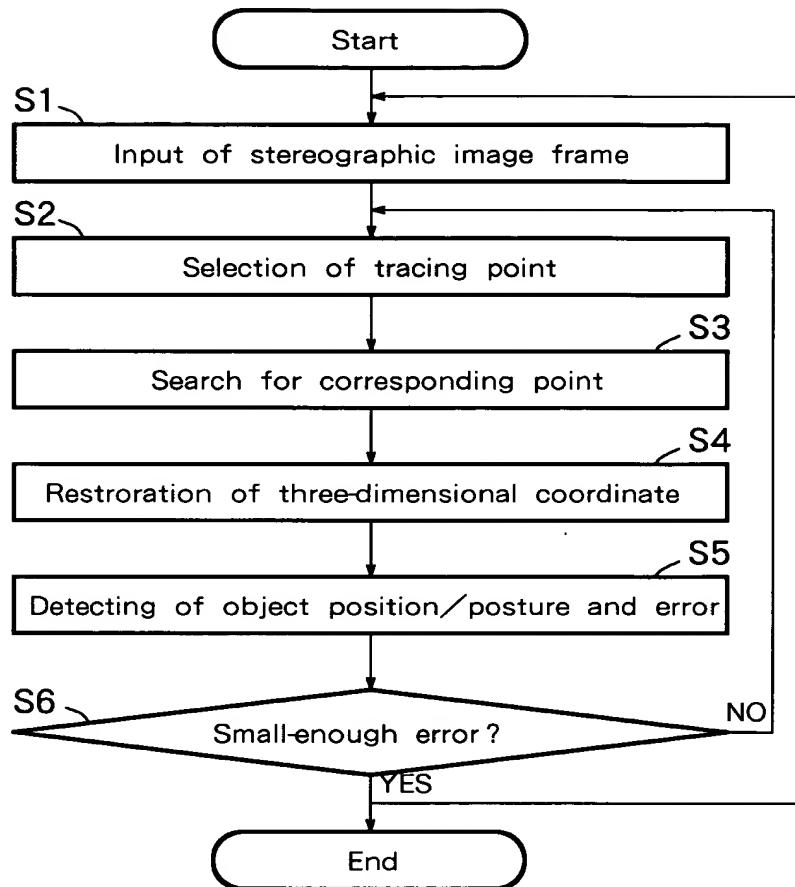


FIG.3

An Example of Time-Series Stereo Image

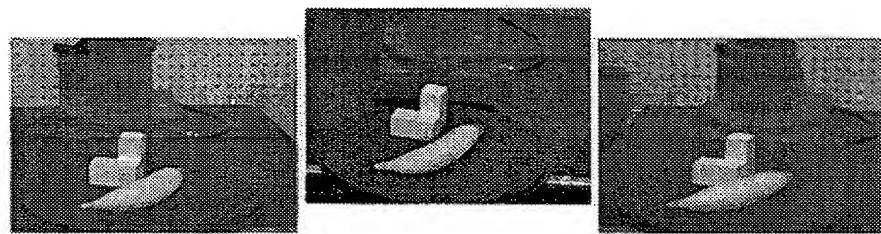


FIG.4

An Example of Estimated Initial Position of a Curve-Faced Object

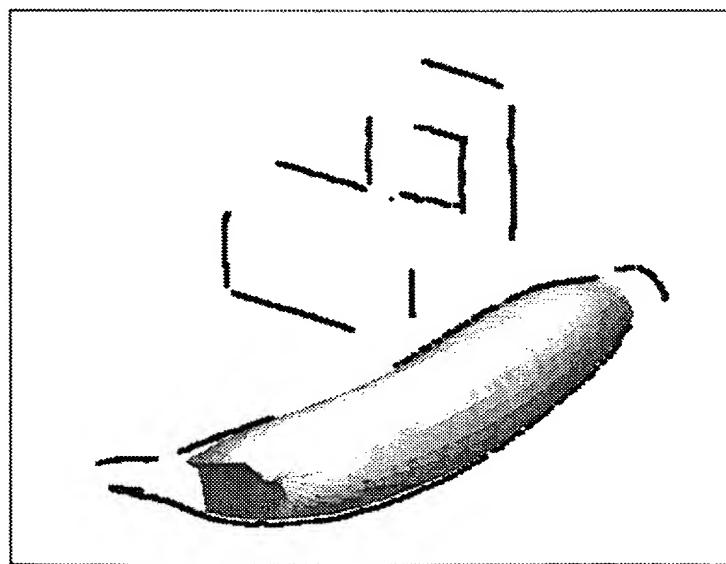


FIG.5

An Example of Net Configuration of a Curve-Faced Object Model

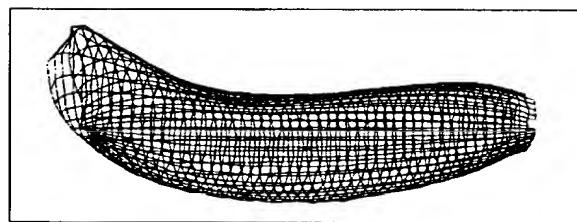


FIG.6

Method of Searching for a Corresponding Edge Point

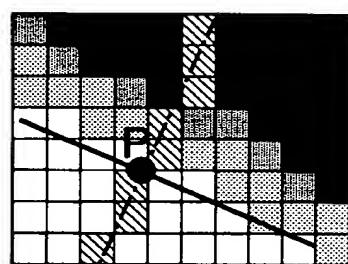


FIG.7

Method of Searching for a Stereo Corresponding Point

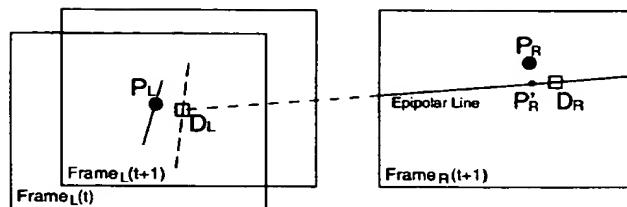


FIG.8

Method of Three-Dimensional Estimation of a Corresponding Point by Monocular Vision

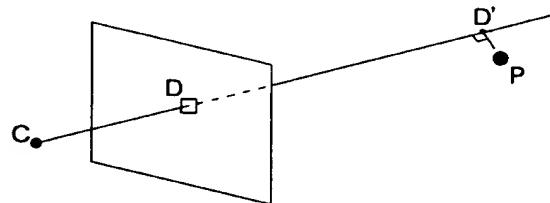


FIG.9

Measurement Error of a Curve-Faced Object in Stereo Vision

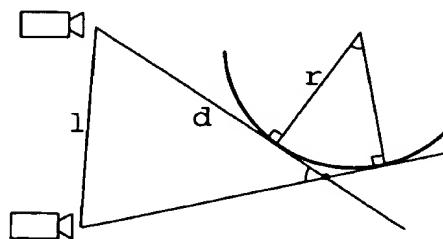
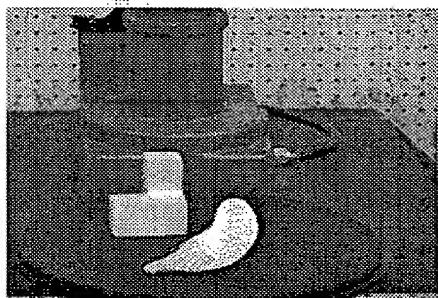
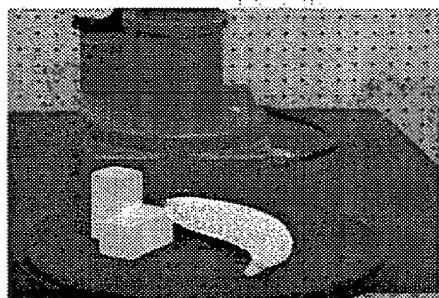


FIG. 10

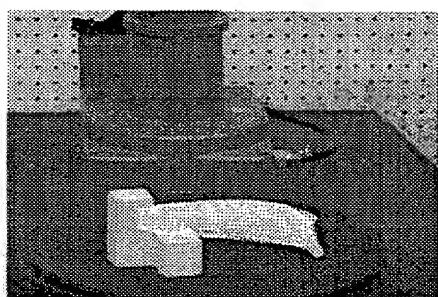
An Example of a Tracing Result of an Arbitrarily-Curved Object



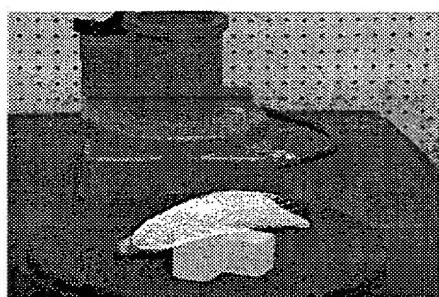
Frame 20



Frame 70



Frame 120



Frame 170

0 9 8 7 6 5 4 3 2 1 0